IN THE CLAIMS:

1-25. (Cancelled)

26. (Currently Amended) A method for recognizing a structure to be applied onto a substrate, the structure being at least one [[of an]] adhesive line ~~or adhesive line~~, the method comprising:

applying the structure onto the substrate by an application facility having a plurality of cameras; and

monitoring the structure applied onto the substrate by the application facility utilizing the cameras, the cameras having at least one overlapping area directed at the applied structure, wherein the edges of the adhesive line of the applied structure~~, in particular the edges of the adhesive line, is~~ are determined on a virtual surrounding track around the application facility, and wherein the applied structure virtually intersects the surrounding track after being applied onto the substrate.

27. (Previously Presented) The method according to claim 26, wherein the surrounding track comprises a closed form around the application facility for determining the adhesive line, the adhesive line on the surrounding track is monitored by means of a projection.

28. (Previously Presented) The method according to claim 26, wherein the adhesive line on the surrounding track comprises a circular caliper.

29. (Previously Presented) The method according to claim 26, wherein the adhesive line on the surrounding track comprises at least one of an elliptical form, a circular form, a polygonal form, and a plurality of continuous lines.

30. (Previously Presented) The method according to claim 26, wherein a center point of the surrounding track coincides with a site that corresponds to a site projected on the substrate by

the application facility with regard to the adhesive line.

31. (Previously Presented) The method according to claim 26, wherein the cameras comprise at least three cameras to monitor the applied structure around the application facility on the surrounding track, wherein each camera utilizes one overlapping area to the neighboring camera.

32. (Previously Presented) The method according to claim 31, wherein each camera monitors a part of the surrounding track such that the camera image monitoring the individual parts of the surrounding track that are joined with the corresponding overlapping areas monitored by each camera to form a continuous surrounding track that progresses on the substrate and around the application facility.

33. (Previously Presented) The method according to claim 26, wherein each camera monitors a segment of the surrounding track, the track essentially in the form of a circular line forming a circular caliper.

34. (Previously Presented) The method according to claim 33, wherein angle values of the circular line range from 0° to 360° to form a global coordinate system, wherein a segment of the circular line having adjacent overlapping areas is assigned to the images of the individual cameras.

35. (Currently Amended) The method according to claim 34, wherein a first camera covers at least a range of angles from about [[100°]] -10° to 130°, a second camera at least a range of angles from about 110° to 250°, and a third camera at least a range of angles from about 230° to 10°.

36. (Previously Presented) The method according to claim 34, wherein one camera

automatically switches to the next camera when the adhesive line progresses from the segment of the circular line of one camera via the overlapping area to the segment of the circular line of a different camera.

37. (Previously Presented) The method according to claim 26, wherein a strip of the camera image is processed by each camera comprising a sequence of images from the individual strips of the camera images wherein the closed surrounding track is assembled from the strips of the individual camera images.

38. (Previously Presented) The method according to claim 26, wherein the individual cameras are calibrated in order to assign an angle assignment, wherein a circular arc or circular line of the calibrating facility having marker points at 0°, 120°, and 240° for three cameras is used.

39. (Currently Amended) An apparatus for recognizing a structure to be applied onto a substrate, the structure is at least one of an adhesive line or adhesive line, comprising:

at least one illumination module; and

one sensor unit having at least two cameras with at least one overlapping area, the cameras are configured around the facility for applying the structure such that each camera is directed at the facility for applying the structure, and wherein ~~the applied structure, in particular~~ the edges of the adhesive line[[, is]] of the applied structure are determined on a virtual surrounding track around the application facility, and wherein the surrounding track is predefined such that the applied structure virtually intersects the surrounding track after being applied onto the substrate.

40. (Previously Presented) The apparatus according to claim 39, wherein an axial longitudinal axis of the individual cameras approximately intersects, in the direction of view, an axial longitudinal axis of the application facility.

41. (Previously Presented) The apparatus according to claim 39, wherein at least three cameras are utilized, the cameras are arranged at equal distances from each other in a direction of the circumference.

42. (Previously Presented) The apparatus according to claim 39, wherein the individual cameras are configured such that images of all the cameras are stored in a sequence of images.

43. (Currently Amended) The apparatus according to claim 42, wherein each camera records a strip of the [[image]] images to form a part of a sequence of images.

44. (Previously Presented) The apparatus according to claim 39, wherein the cameras form the surrounding track approximately comprise a circular caliper.

45. (Previously Presented) The apparatus according to claim 44, wherein a center of the circular caliper approximately coincides with a site that corresponds to the longitudinal axis of the application facility on the substrate.

46. (Previously Presented) The apparatus according to claim 39, wherein each camera monitors a part of the surrounding track such that the individual parts of the surrounding track monitored by each camera is joined with the corresponding overlapping areas monitored by each camera to form a continuous surrounding track that progresses on the substrate around the application facility as a monitoring area.

47. (Previously Presented) The apparatus according to claim 39, wherein each individual camera comprises an overlapping area relative to the next camera of at least one of a 10° overlapping area and a 30° to 90° overlapping area.

48. (Currently Amended) The apparatus according to claim 39, further ~~comprises~~ comprising a calibrating device, the calibrating device comprising individual form elements utilized for calibrating the individual cameras for the assignment of the angle assignment, wherein the individual form elements comprise an angle distance of approximately 10°.

49. (Previously Presented) The apparatus according to claim 48, wherein the calibrating device comprises at least three marker sites that are configured to be arranged in a circular arc of the calibrating device approximately at 0°, 120°, and 240° to calibrate the three cameras.

50. (Previously Presented) The apparatus according to claim 49, wherein the marker sites extend in an angle range of approximately 10°, and the marker sites comprise at least two form elements.

51. (New) The method according to claim 26, wherein the cameras comprise only three cameras to monitor the applied structure around the application facility on the surrounding track, wherein each camera utilizes one overlapping area to the neighboring camera.

52. (New) The apparatus according to claim 39, wherein only three cameras are utilized, the cameras are arranged at equal distances from each other in a direction of the circumference.